**CLAIMS:**

1.        A computer-implemented method for controlling a robot (41), the method comprising the steps of:

        (a)        supplying a first set of programming statements (20) defining behaviors to be performed by said robot (41) as a first input to a transformation engine (26);

        (b)        supplying a second set of programming statements (22) organized as a plurality of behavioral templates defining rules for interpreting said behaviors as a second input to said transformation engine (26); and

        (c)        transforming, in said transformation engine (26), said behaviors in accordance with said defined rules to yield a third set of robotic programming statements (30) for directly controlling said robot (41).

2.        The method of Claim 1, wherein said first set of programming statements (20) are written in a first high-level programming language.

3.        The method of Claim 1, wherein said second set of programming statements (20) are written in a second high-level programming language.

4.        The method of Claim 2, wherein said first set of programming statements are in the form of an extensible markup language (XML) and the second set of programming statements are in the form of an extensible stylesheet language (XSL).

5.        The method of Claim 3, wherein said first set of programming statements are in the form of an extensible markup language (XML) and the second set of programming statements are in the form of an extensible stylesheet language (XSL).

6.        The method of Claim 1, wherein one of said defined behaviors from said first set of programming statements (20) is associated with one or more of said plurality of behavioral templates from said second set of programming statements (22).

7.        The method of Claim 1, wherein said third set of robotic programming statements (30) are written in a low-level robotic hardware language directly executable by said robot (41).

8.      The method of Claim 1, wherein said transforming step (c) further comprises the steps of:

(1) sequentially selecting said behaviors from said first set of robotic programming statements (20);

(2) for each behavior selected at said step (1), searching said plurality of behavioral templates (22) to locate a behavioral template matching said selected behavior; and

(3) applying said matching behavioral template at said step (2) to said selected behavior at said step (1) to yield at least a portion of said third set of robotic commands (30) for directly controlling said robot (41).

9.      The method of Claim 8, wherein said first set of robotic programming statements (20) are selected from a high-level description file (20).

10.      The method of Claim 1, wherein said first set of programming statements (20) collectively comprise a robotic presentation (40) to be performed by said robot (41).

11.      The method of Claim 10, further comprising the step of combining said at least a portion of said third set of robotic commands (30) with at least one of an audio (29) and/or a video multi-media stream (25) for use in said robotic presentation (40).

12.      A system for controlling a robot via a high-level programming language, the system comprising:

means for supplying a first set of programming statements (20) defining behaviors to be performed by said robot as a first input to a transformation engine (26);

means for supplying a second set of programming statements (22) organized as a plurality of behavioral templates defining rules for interpreting said behaviors as a second input to said transformation engine (26); and

means for transforming, in the transformation engine (26), said behaviors included in accordance with said defined rules to yield a third set of robotic commands (30) for directly controlling said robot (41).

13.      The system of Claim 12, wherein said means for transforming further comprises:

means for sequentially selecting said behaviors from said first set of robotic programming statements (20);

means for searching said plurality of behavioral templates (22) for each selected behavior to locate a behavioral template matching said selected behavior; and

5      means for applying said matching behavioral template to said selected behaviors to yield at least a portion of said third set of robotic commands (30) for directly controlling said robot (41).

14.      The system of Claim 13, wherein said behavioral templates are searched in a first high-level description file (20).

15.      The system of Claim 13, wherein said behaviors are selected from a

10    second high-level description file (22).